

CLAIM AMENDMENTS

1. (CURRENTLY AMENDED) A method for determination of and compensation for a ~~the~~ scale factor error caused by changes in the wavelength of a multiple axis fiber-optic gyroscope (FOG) which is fed from a common light source, in a GPS-supported inertial track and attitude reference system that ~~there~~ is equipped with Kalman correction wherein the scale factor error determined for an axis with comparatively fast motion dynamics relative to the motion dynamics of the other axes is used as the Kalman filter correction value for the scale factor error correction for all of the measurement axes of the FOGs with slower dynamics, with the error correction being carried out with a time constant which is long in comparison to expected short-term error sources which cannot be modulated or compensated for.

2. (PREVIOUSLY AMENDED) The method as claimed in Claim 1 for a three-axis track and attitude reference system, wherein the scale factor error determined for the vertical axis (z) is used for error compensation for the other measurement axes (x, y) for scale factor error correction.

3. (CANCELED)